

Figure 1: Overview of Potential Behavior Recognition System Use.

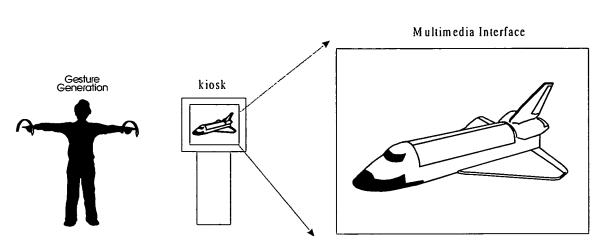


Figure 2: Gesture Recognition System.

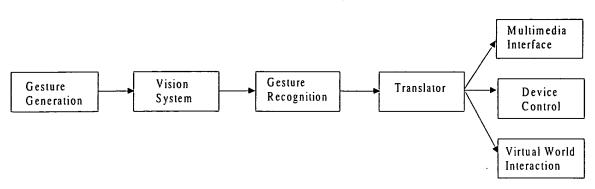


Figure 3: Gesture Recognition System Flow Chart.

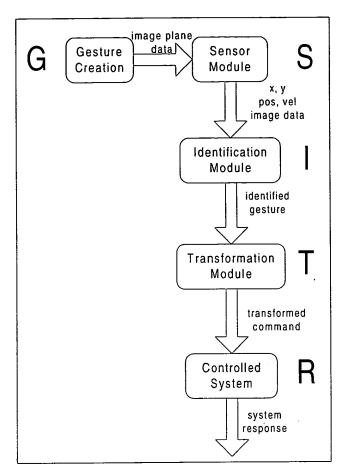


Figure 4: Signal Flow Diagram of the Gesture Recognition System.

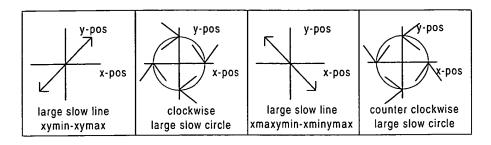


Figure 5: Example gestures, showed in two dimensions.

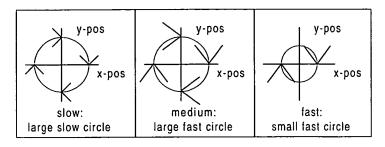


Figure 6: Three Example Gestures.

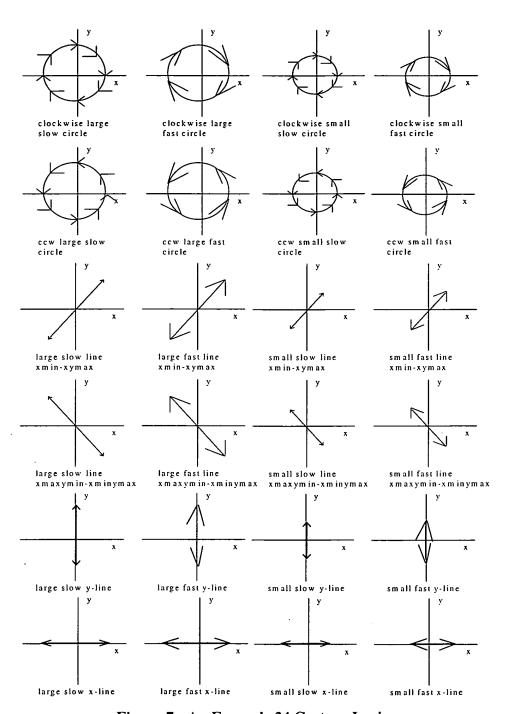


Figure 7: An Example 24 Gesture Lexicon.





DAY

Extend the arm horizontally sideward, patin to the front: wave the erm slightly-downword soveral times, kenging the arm site ght. Do not move armadown horizontal

NIGHT

Hold a light at shoulder level; blink it several times toward the vehicle.

Figure 2-12. SLOW DOWN.

Figure 8: Slow Down Gesture.





Simulate tranking of engines by moving the erm, with the first, in a circular motion as weight level.

NIGHT

Move a light to describe a horizontal liquire 8 in a vertical plane in from of body.

Figure 2-6. START ENGINE, or PREPARE TO MOVE

Figure 9: Prepare to Move Gesture.



Figure 2-1, ATTENTION.

Figure 10: Attention Gesture.

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NIGHT

Pales the hand upward to the full ex-tent of the arm, palm to the tront, forth several times across the path of ap-hold that position until the signal is understood. When the same signal to stop whiches. Use

NOTE: For alternate algoral to stop vehicles, see Figure 2-17.

Figure 2-7 HALT or STOP.

Figure 11: Stop Gesture.



DAY Expand the rum hardsontally to eide, palm outwerd.

NIGHT
Rotate a light to describe a circle 12 to 18 inches in diameter in the direction of the turn.

FIGURE \$12. FIGHT on LEFT TURN.

Figure 12: Right or Left Turn Gestures.



Hold the flet out with thumb up.

Figure 2-22, MESSAGE ACKNOWLEDGED.

Figure 13: "Okay" Gesture.

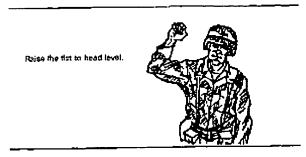


Figure 243 FREEZE

Figure 14: Freeze Gesture.

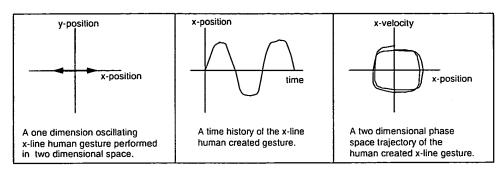


Figure 15: Plots of a Human Created One Dimensional X-Line Oscillating Motion.

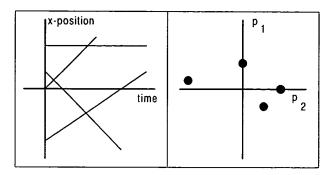


Figure 16: Possible Lines Associated with x(t,p)=p0+p1t and Their Equivalent Representation in the p Parameter Space.

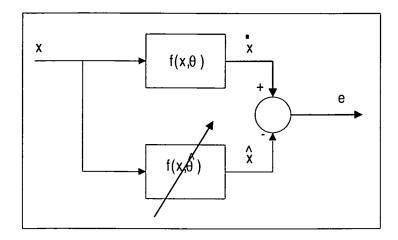


Figure 17: Parameter Fitting: We Require a Rule for q to Bring the Error to Zero.

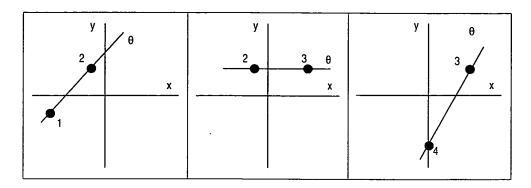


Figure 18: Plots of Different (xi,yi) Data Points that Result in a Different Best Fitting q Line.

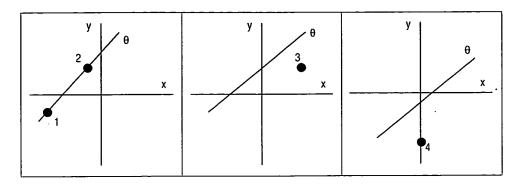


Figure 19: The Recursive Linear Least Squares Method for Updating q with Each Additional (xi,yi) Data Point.

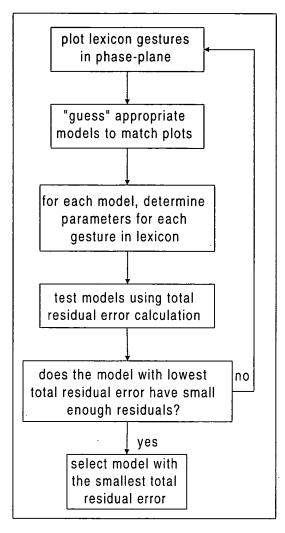


Figure 20: An Algorithm for Determining the Specific Gesture Model.

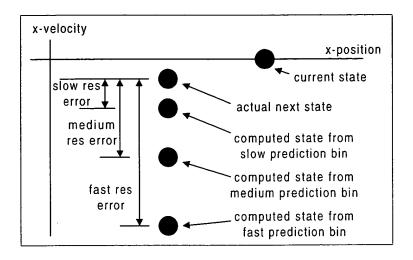


Figure 21: An Exaggerated Representation of the Residual Error Measurement.

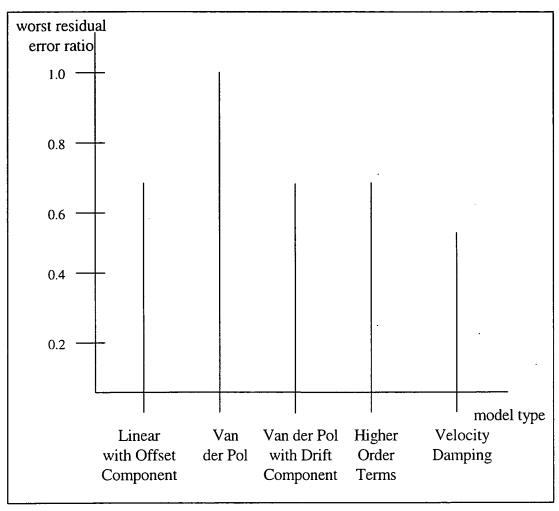


Figure 22: The Worst Case Residual Ratios for Each Gesture Model. The Lower the Ratio, the Better the Model.

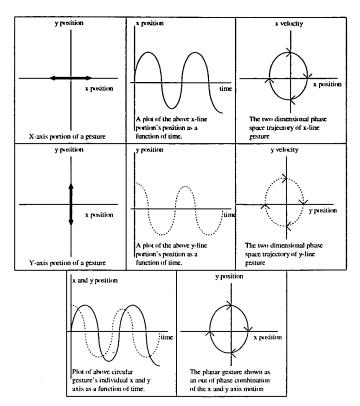


Figure 23: Two Perpendicular Oscillatory Line Motions Combined into a Circular Gesture.

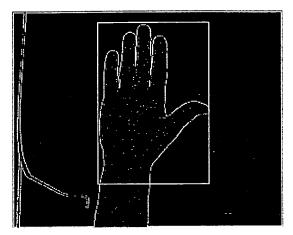


Figure 24: Bounding Box Around Hand.

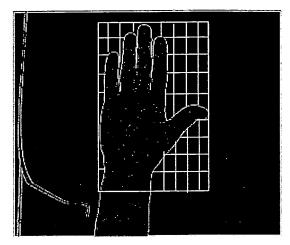


Figure 25: Descriptions from Bounding Box.

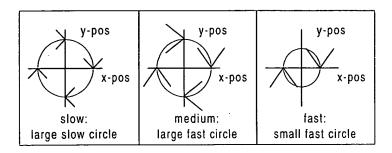


Figure 26: The Example Gestures.

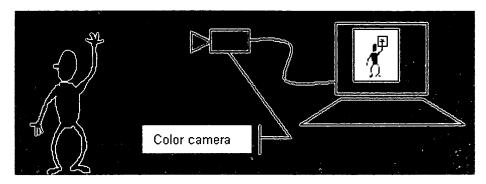


Figure 27: Schematic of the Hand Tracking System Hardware.

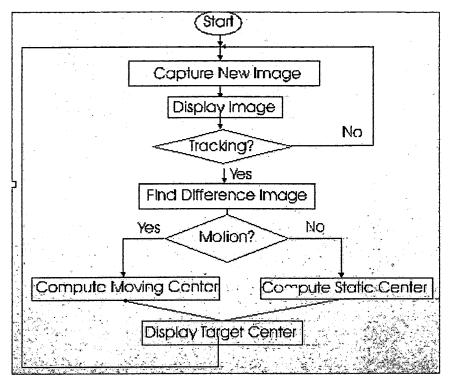


Figure 28: Flowchart of the CTS.

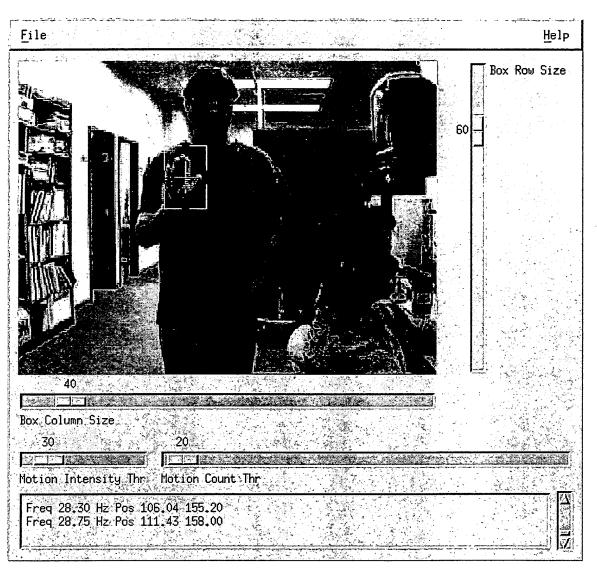


Figure 29: Graphical User Interface of the CTS.

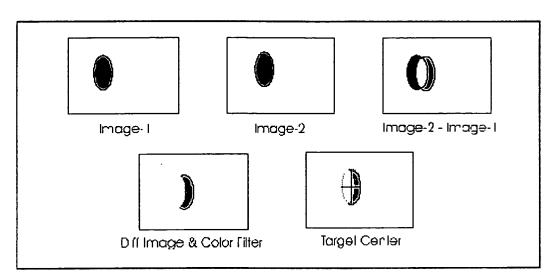


Figure 30: Target Center from Difference Image.

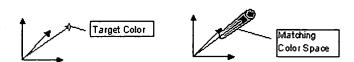


Figure 31: Color Matching Technique.

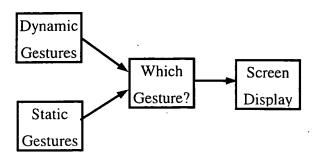


Figure 32: Identification Module.

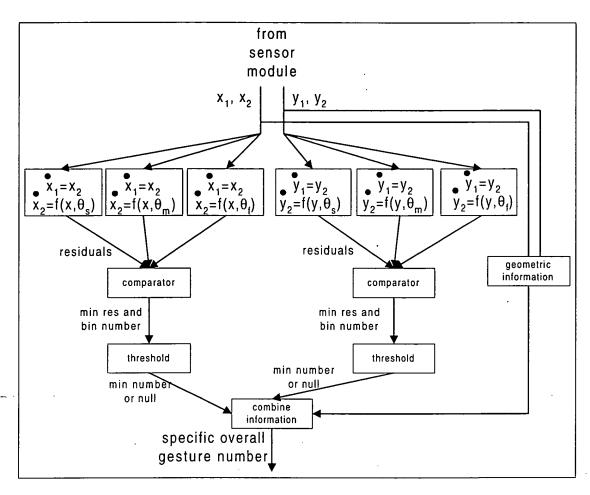


Figure 33: Simplified Diagram of the Dynamic Gesture Prediction Module.

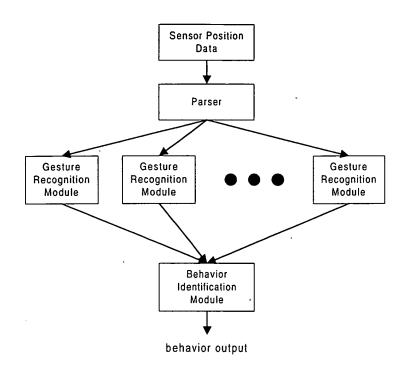


Figure 34: Behavior Recognition Module.